

FIG. 1

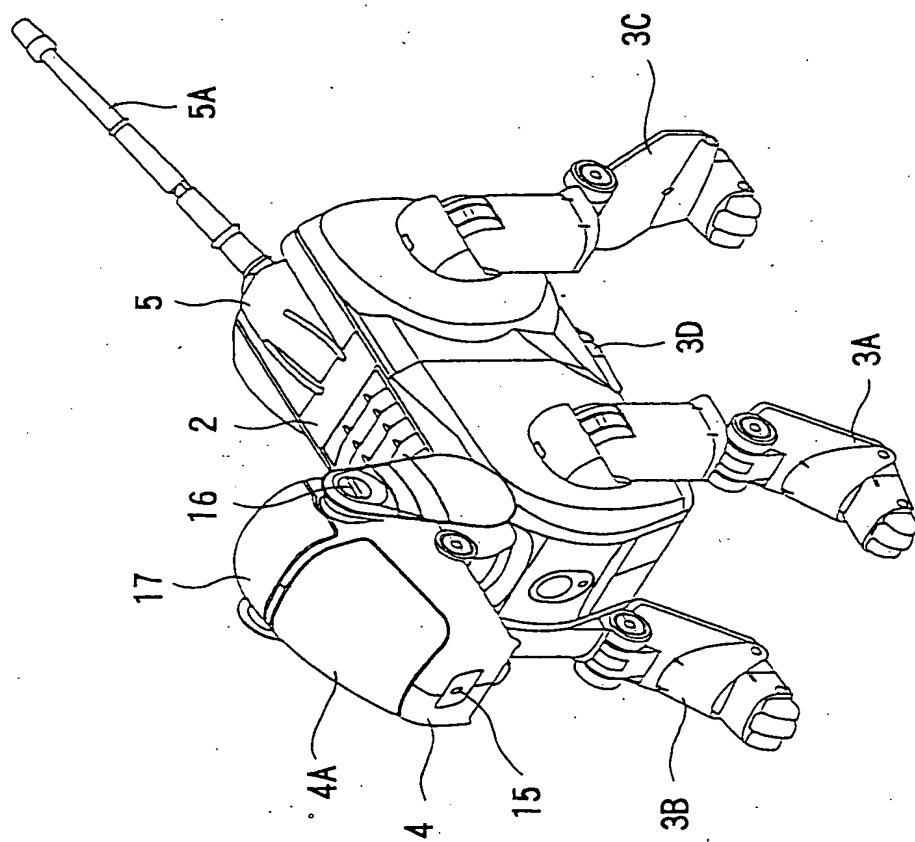


FIG. 1



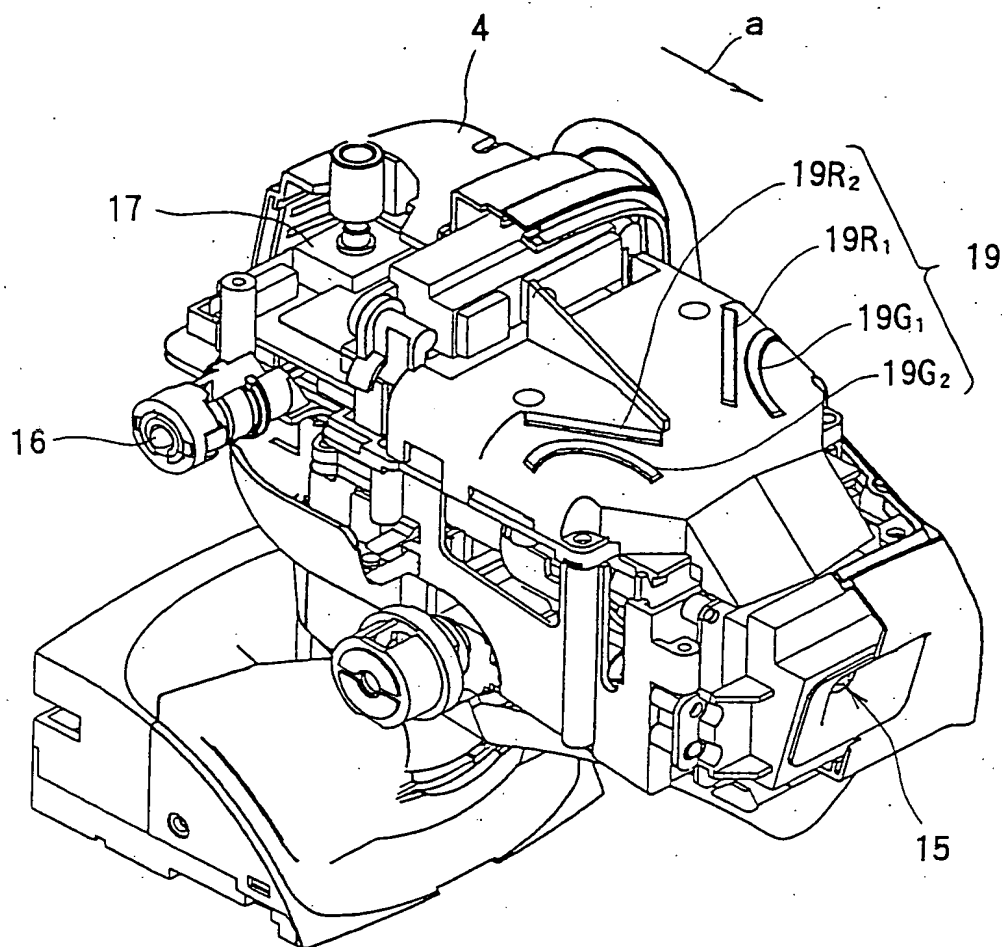


FIG. 3

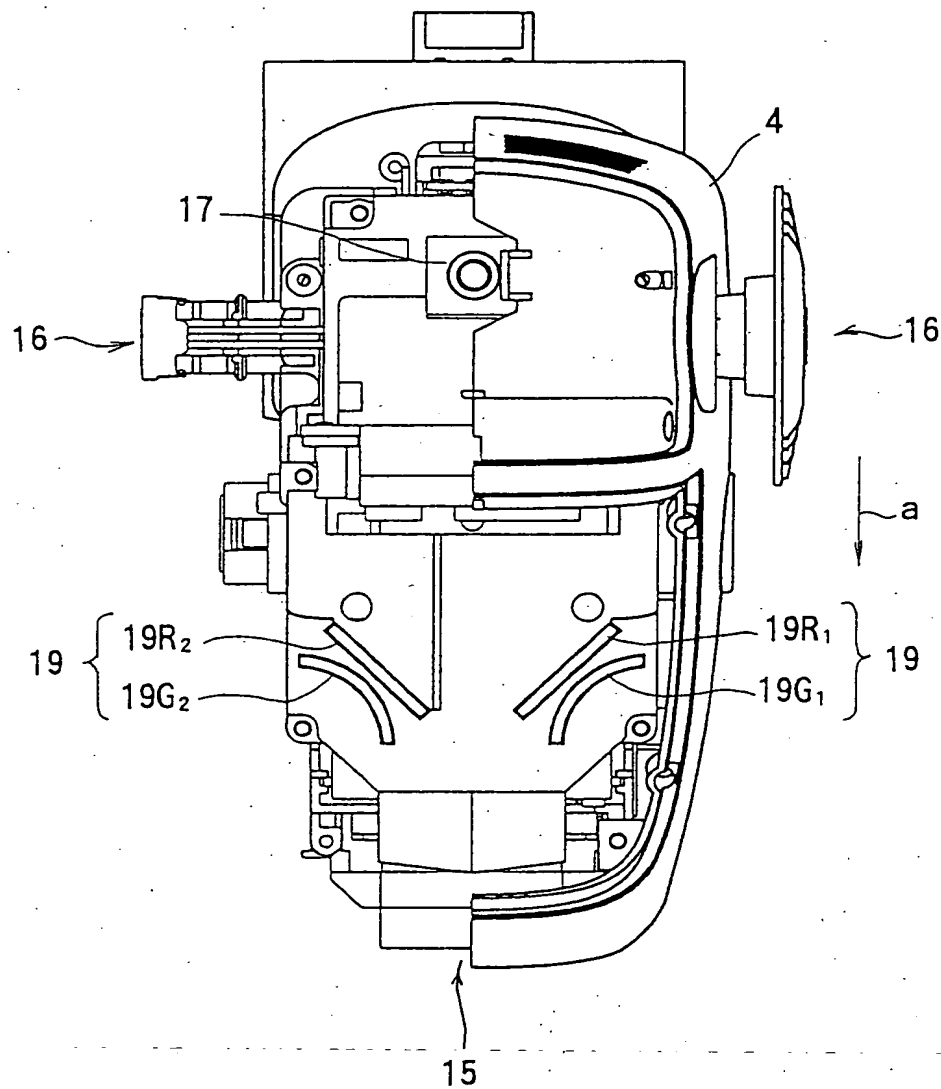


FIG. 5

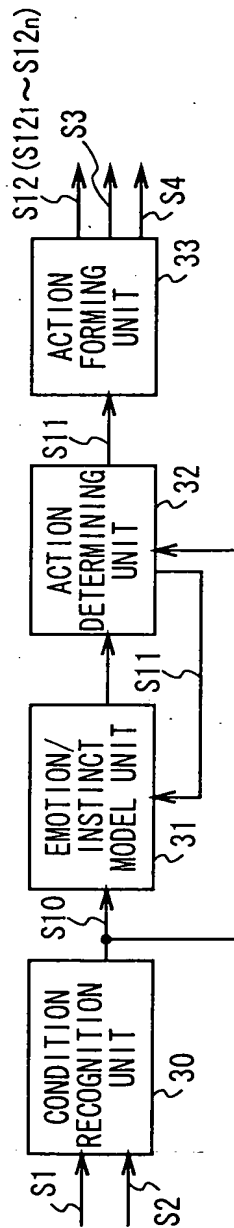


FIG. 5

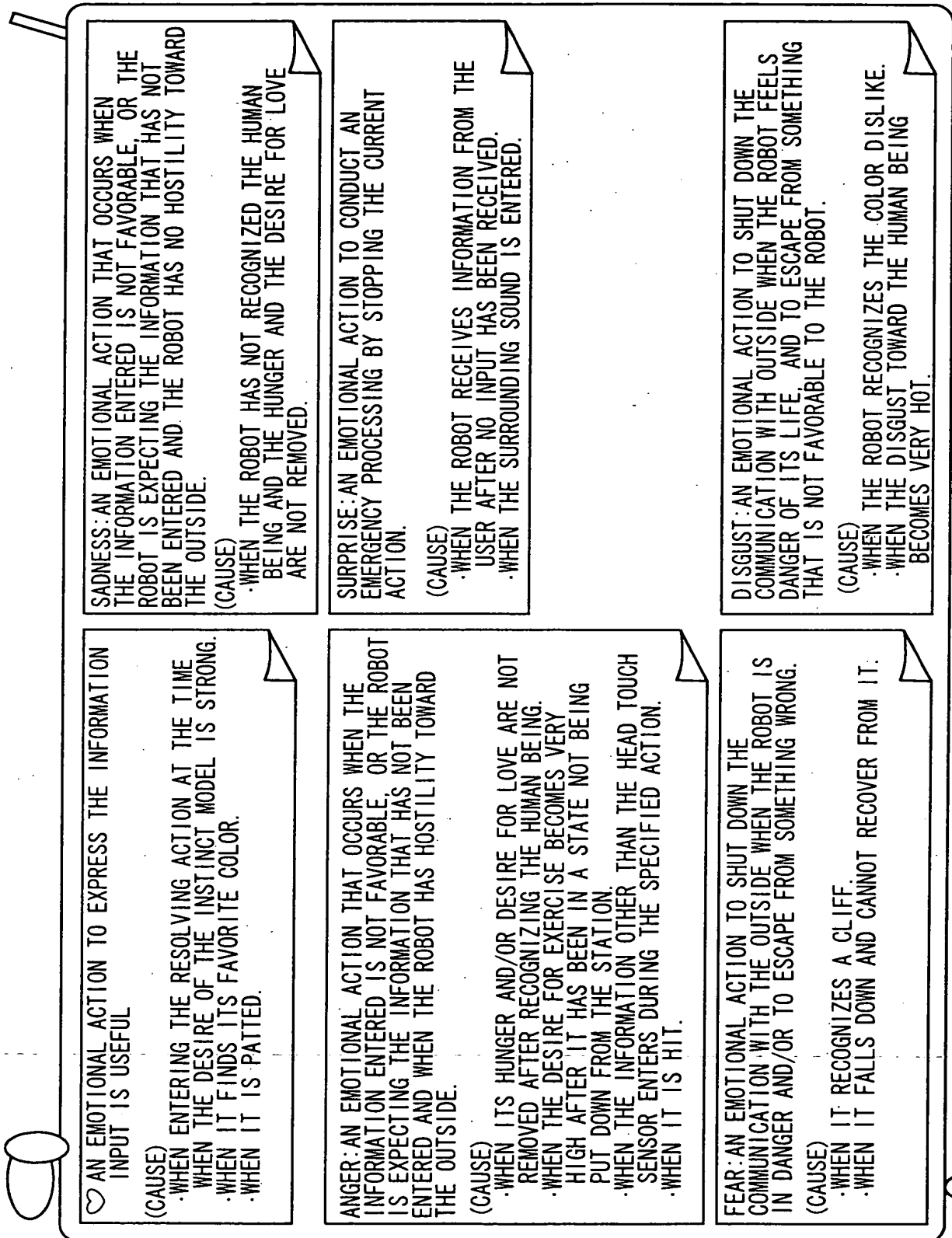


FIG. 6

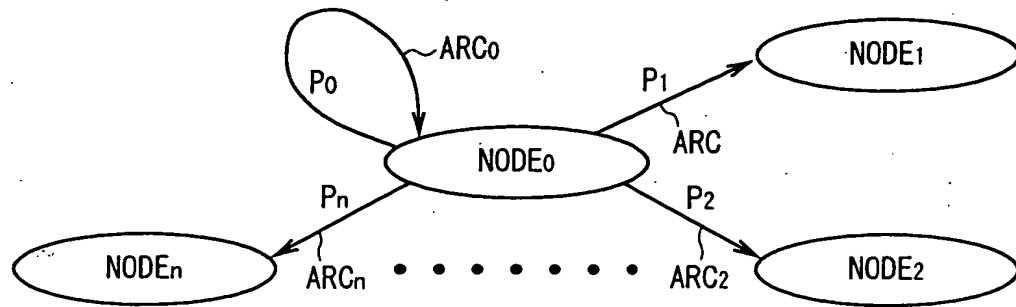


FIG. 7

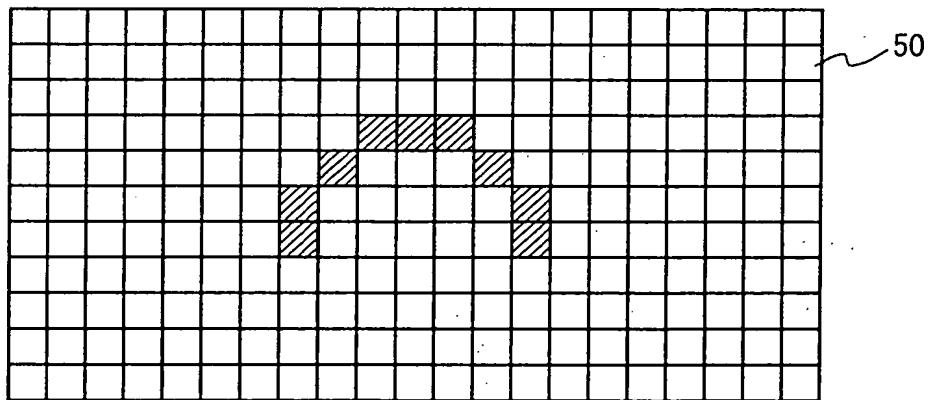


FIG. 9

NODE OF TRANSMITTING END OUTPUT ACTION	NAME OF INPUT EVENT		NAME OF DATA		RANGE OF DATA		TRANSITION PROBABILITY TO OTHER NODE			
							A	B	C	D
node 100							node 120	node 120	node 1000	n
							ACTION 1	ACTION 2	ACTION 3	node 600
1	BALL	SIZE			0, 1000		30%			ACTION 4
2	PAT							40%		
3	HIT								20%	
4	SOUND									50%
5	OBSTACLE	DISTANCE			0, 100					
6		JOY			50, 100					
7		SUPRISE			50, 100					
8		SADNESS			50, 100					

40

FIG. 8



## EXPLANATION OF REFERENCE NUMERALS

1 - PET ROBOT, 4 - HEAD UNIT, 4A - SEMI-TRANSPARENT COVER,  
10 - CONTROLLER, 10A - TOUCH SENSOR, 15 - CCD CAMERA, 16 -  
MICROPHONE, 17 - TOUCH SENSOR, 19R<sub>1</sub>, 19R<sub>2</sub> - RED LED, 19G<sub>1</sub>, 19G<sub>2</sub> -  
GREEN LED, 21<sub>1</sub> ~ 21<sub>N</sub> - ACTUATOR, 30 - CONDITION RECOGNITION UNIT,  
31 - EMOTION/INSTINCT MODEL UNIT, 32 - FACTION DETERMINING UNIT,  
33 - ACTION FORMING UNIT, 40 - CONDITION TRANSITION TABLE, S3 -  
AUDIO SIGNAL, S4 - LED DRIVING SIGNAL, S10 - CONDITION RECOGNITION  
INFORMATION, S11 - ACTION DETERMINING INFORMATION, S12 - DRIVING  
SIGNAL